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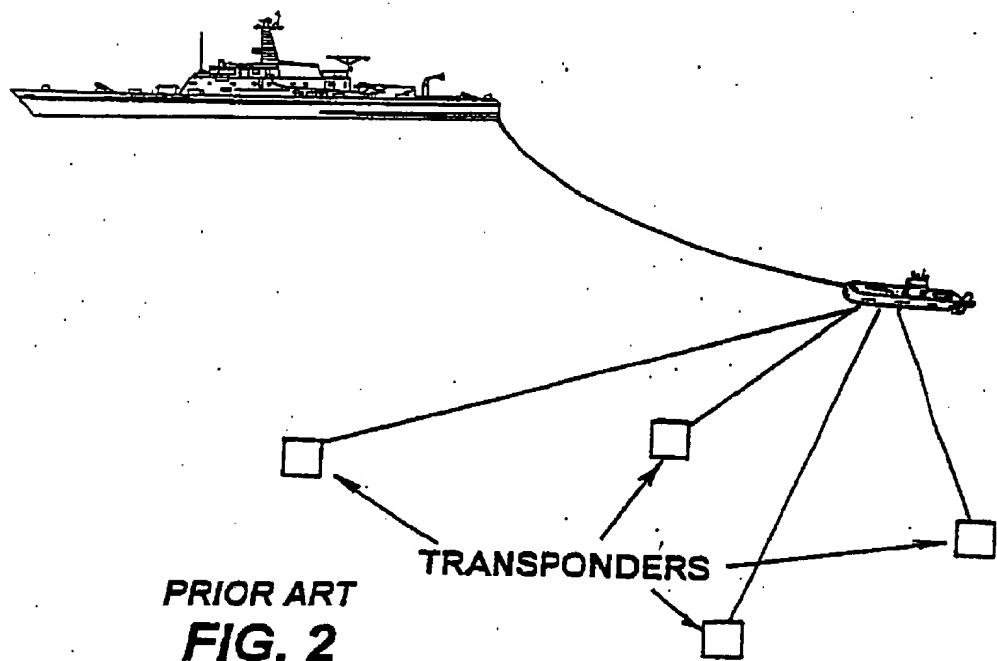
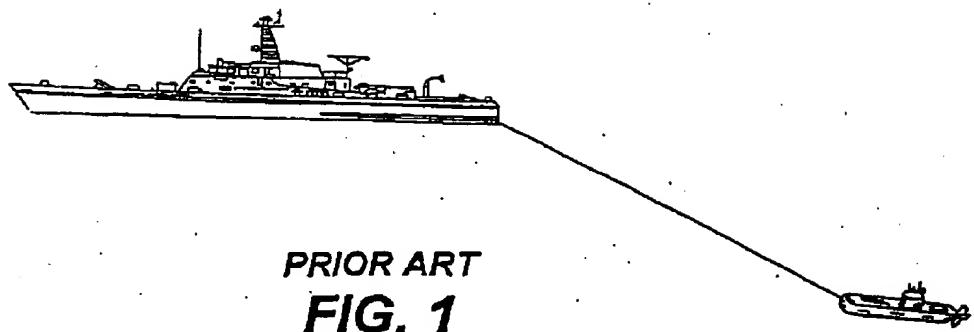
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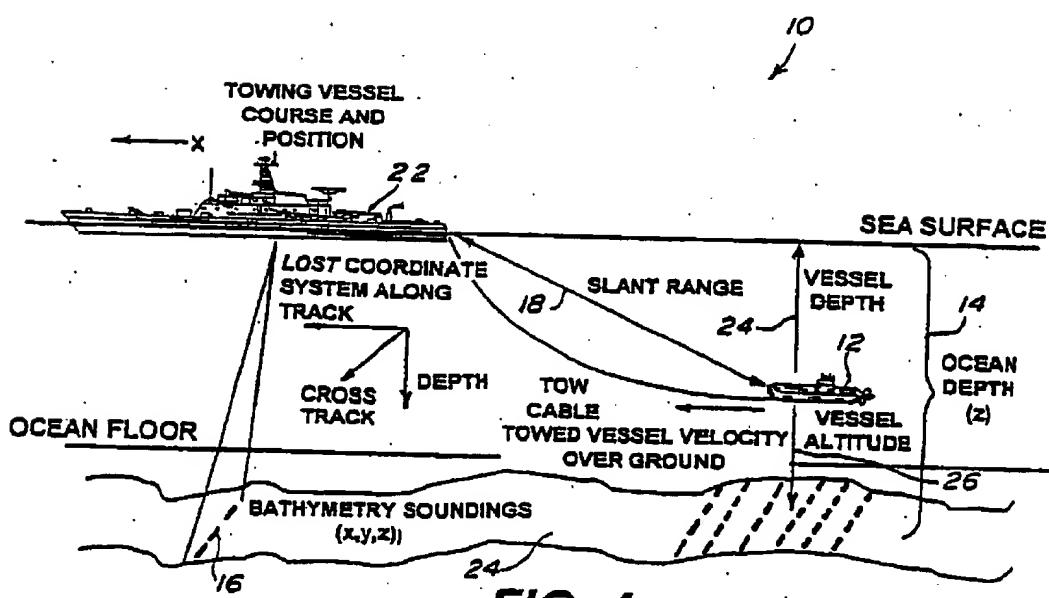
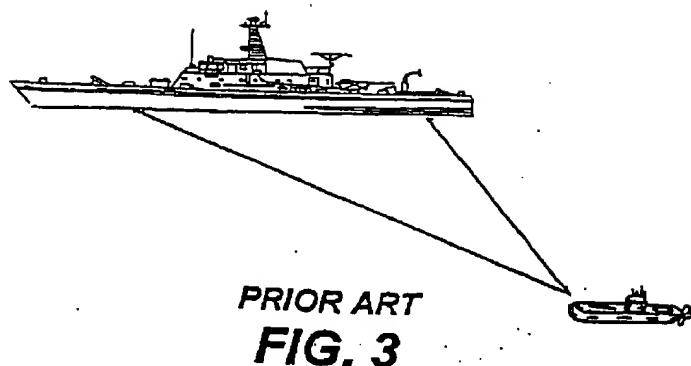
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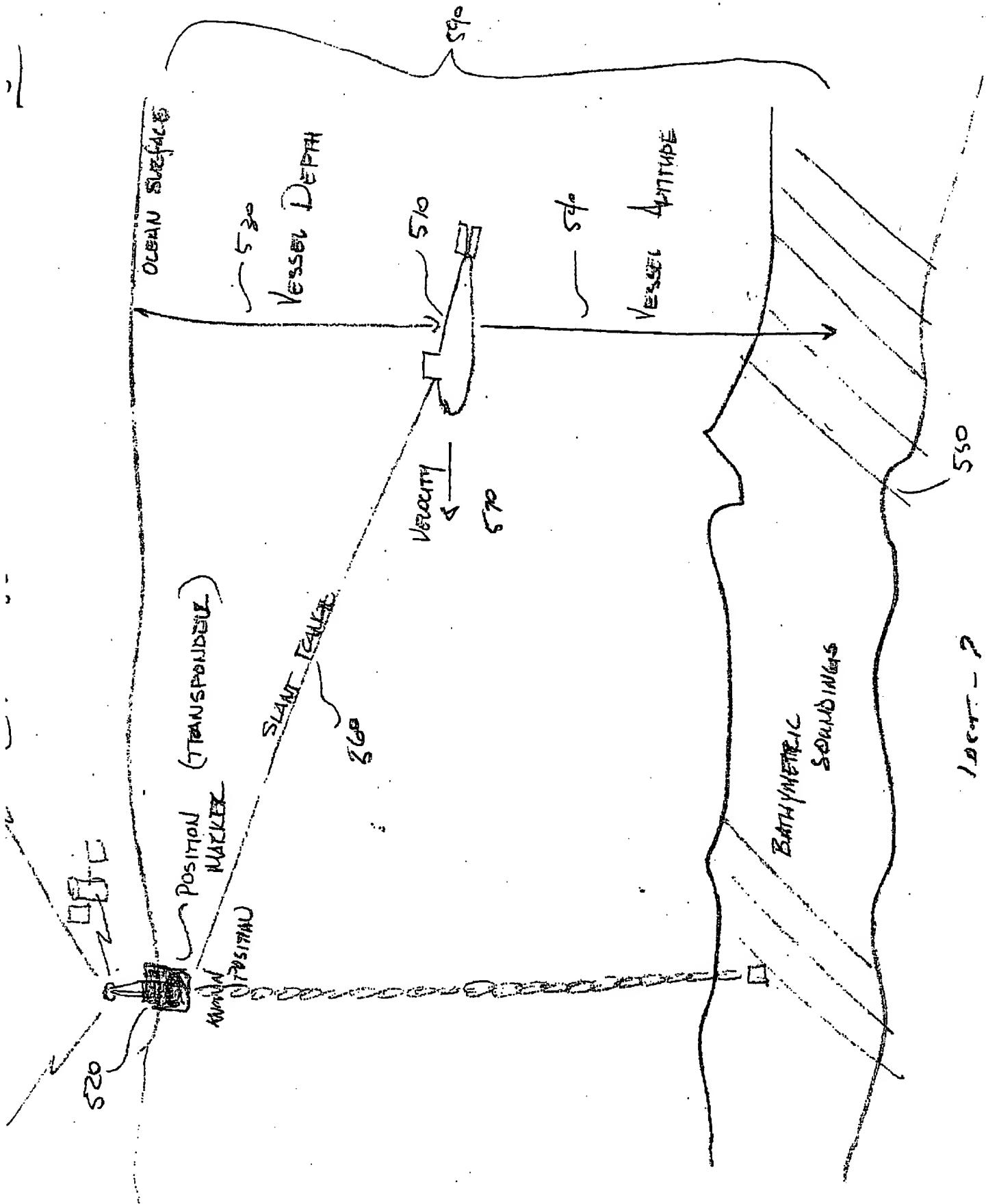
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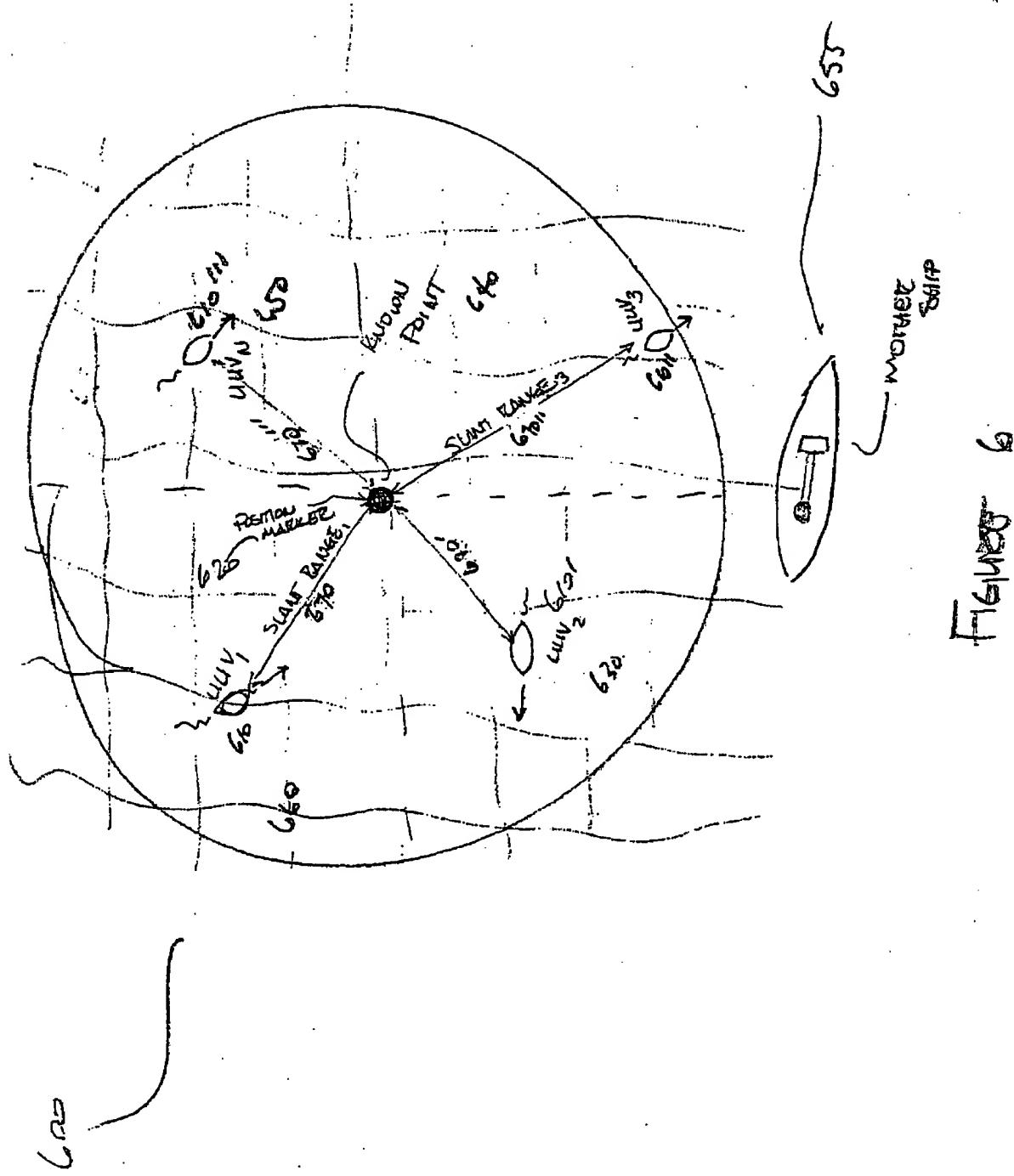


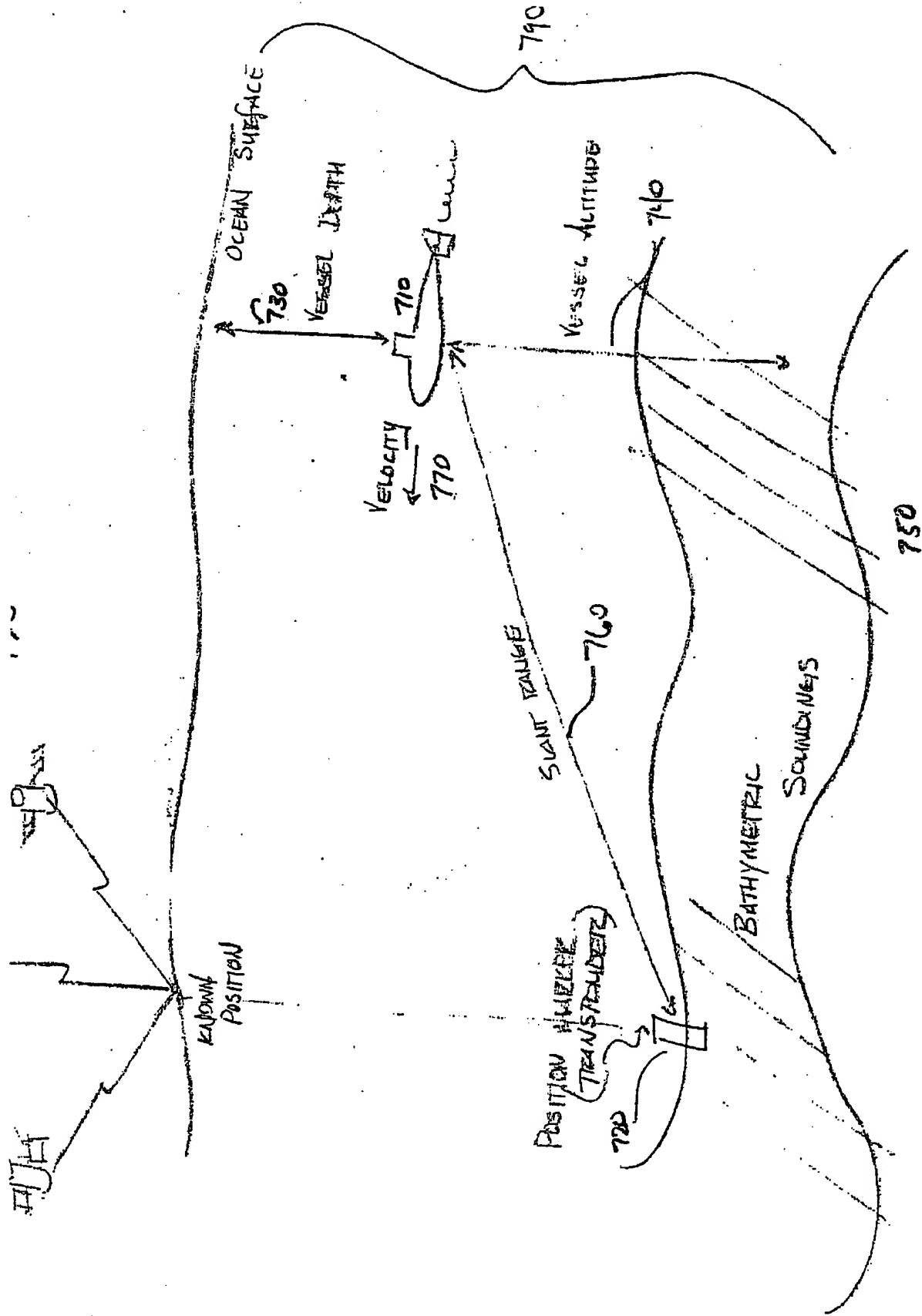


PRIOR ART



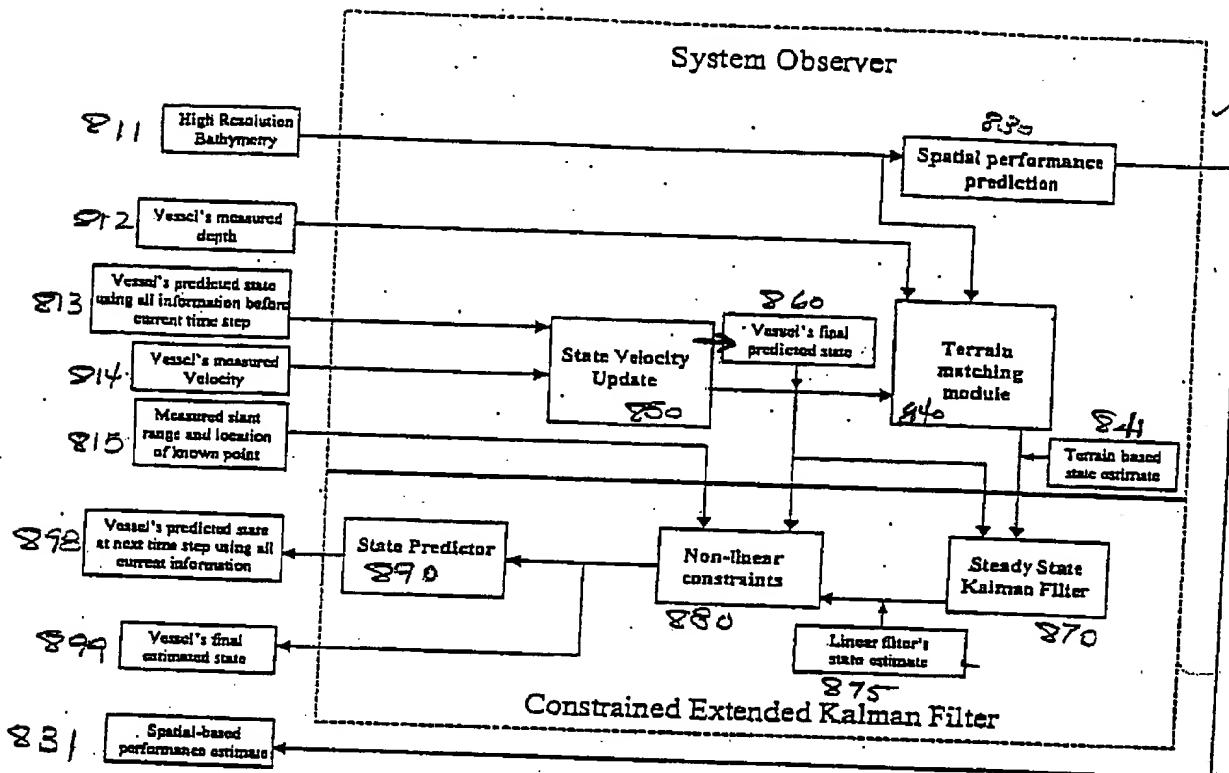
EXAMPLE OF LOST 2 EMPLOYMENT  
MULTIPLE UAVs





L05T-2

FIGURE 7



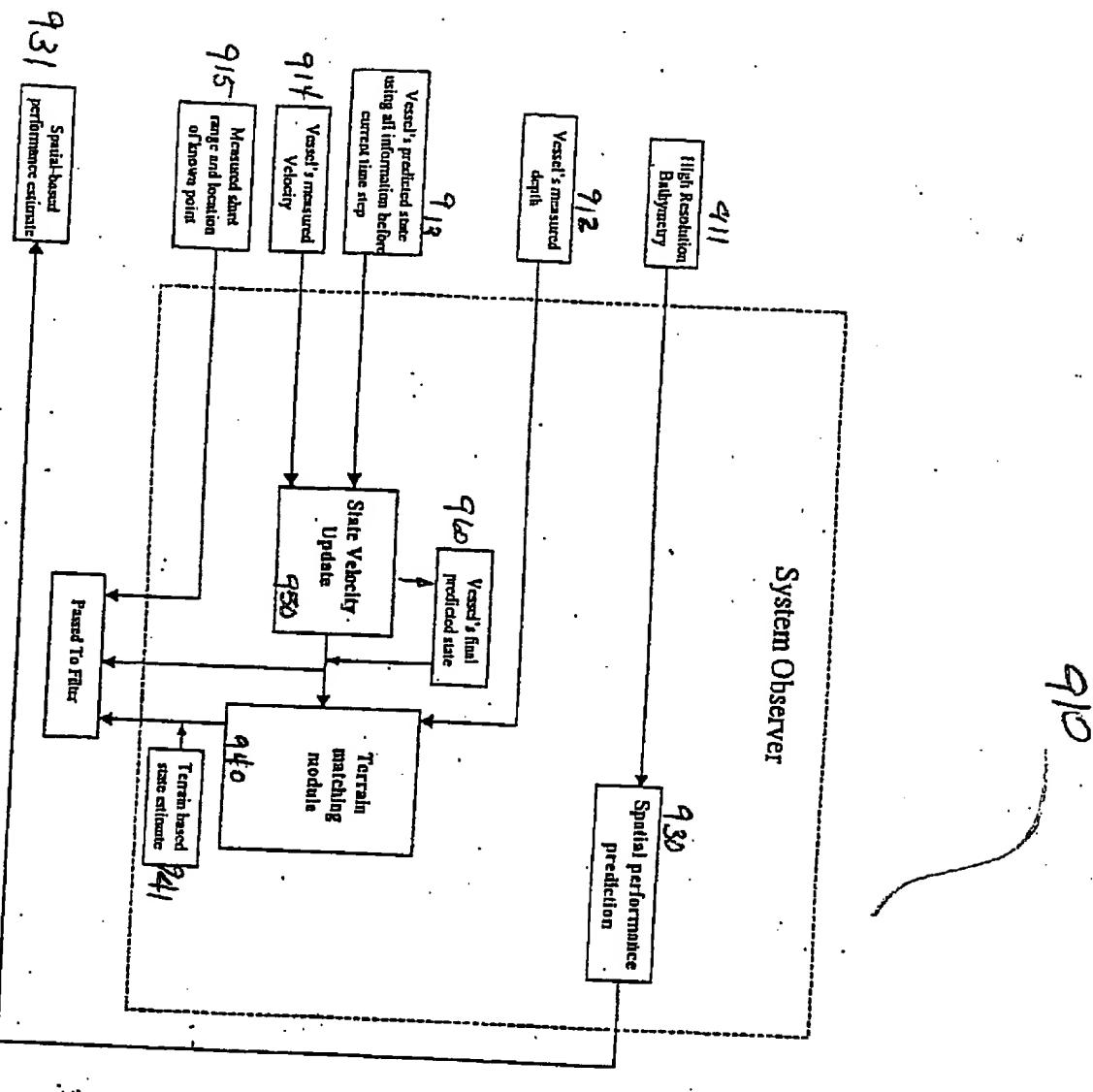
Block diagram of the system showing the two primary subsystems

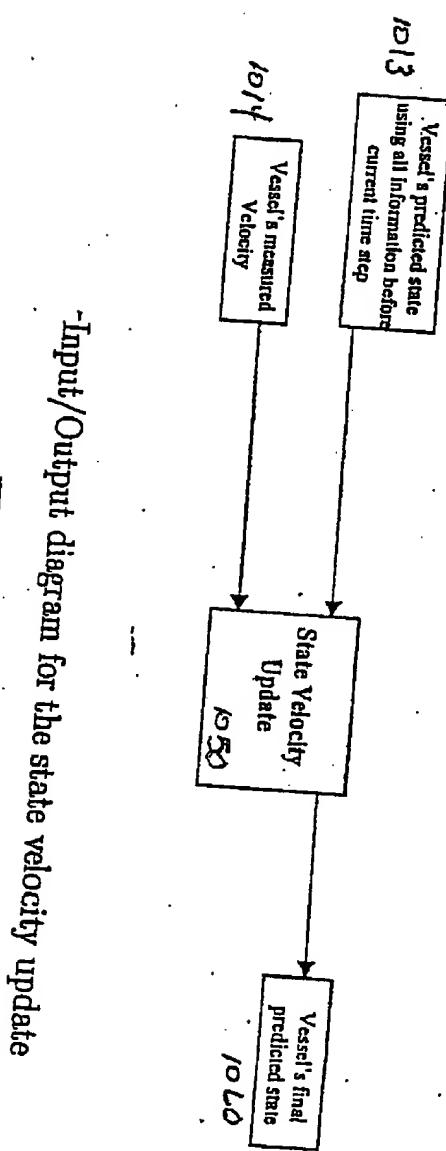
Figure 8.

flow

Block diagram of the system observer subsystem showing the signal

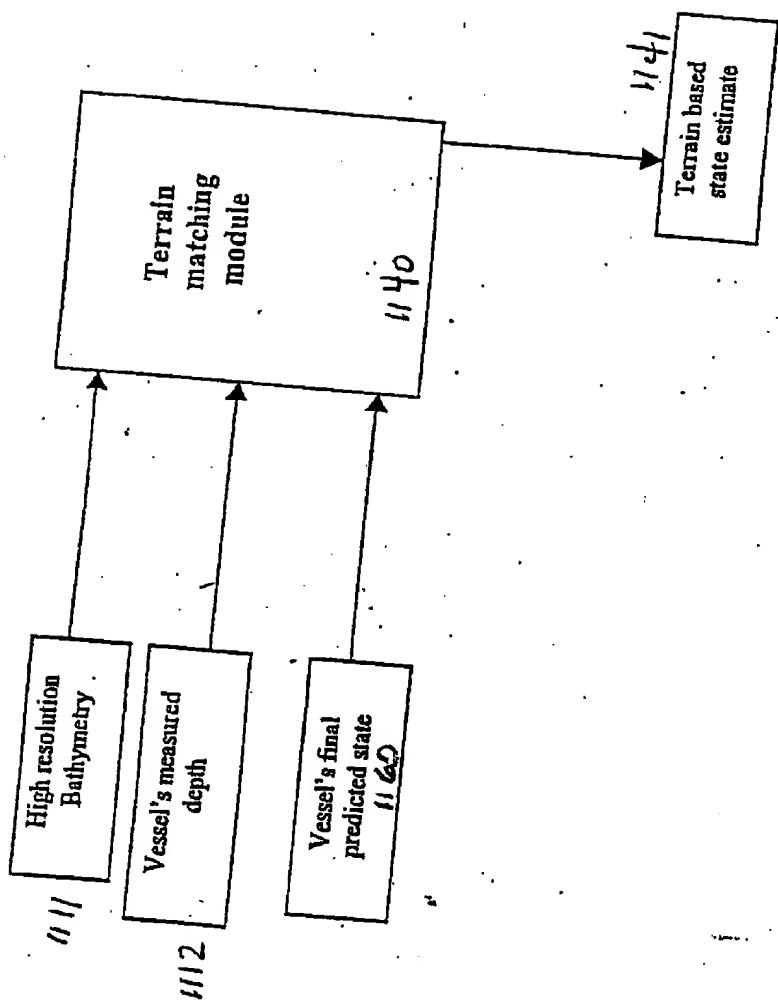
Figure 9





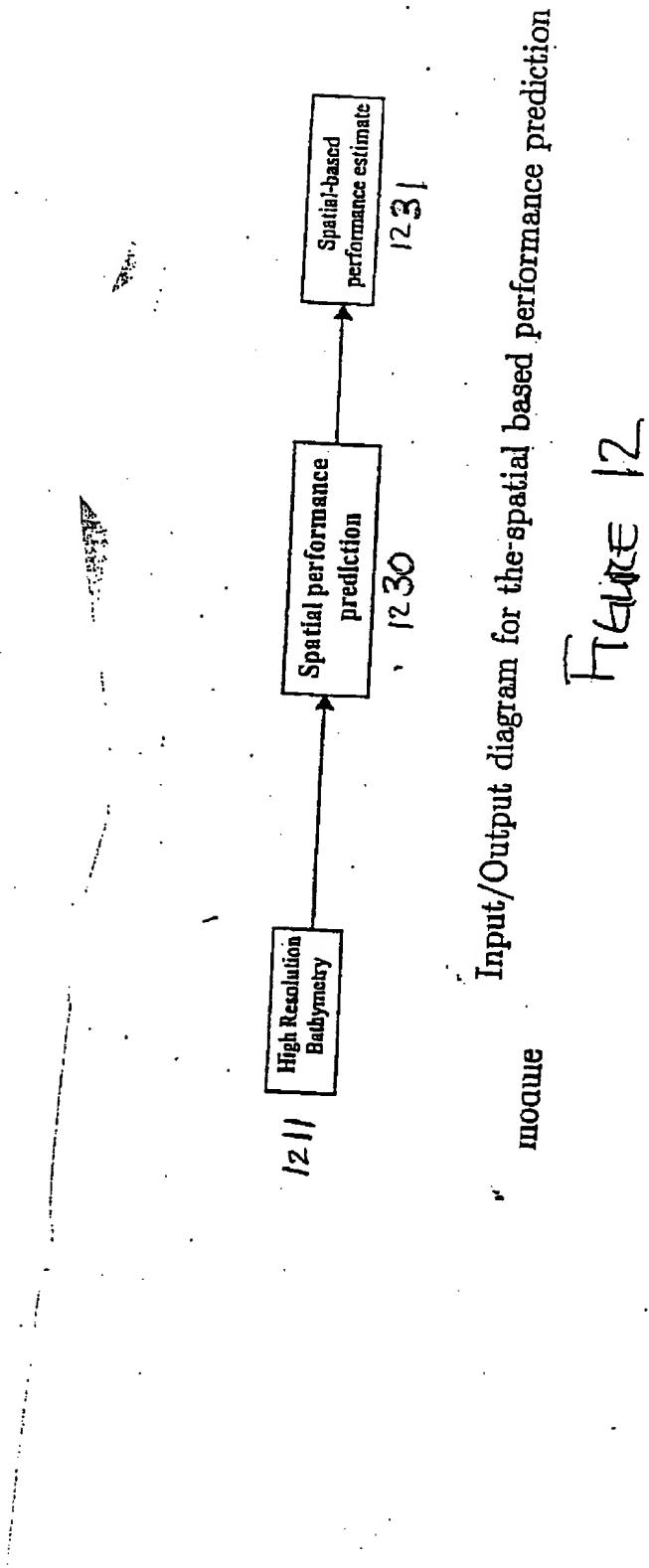
-Input/Output diagram for the state velocity update

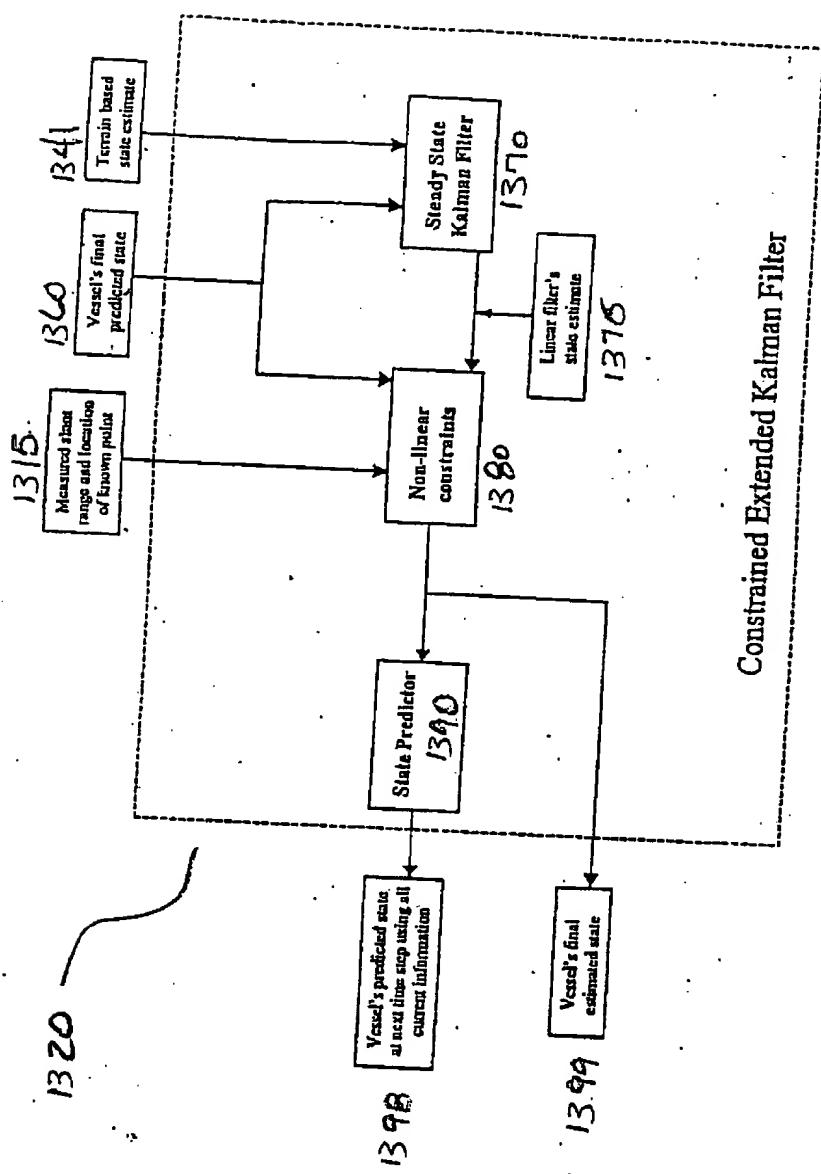
FIGURE 10



Input/Output diagram for the terrain matching module

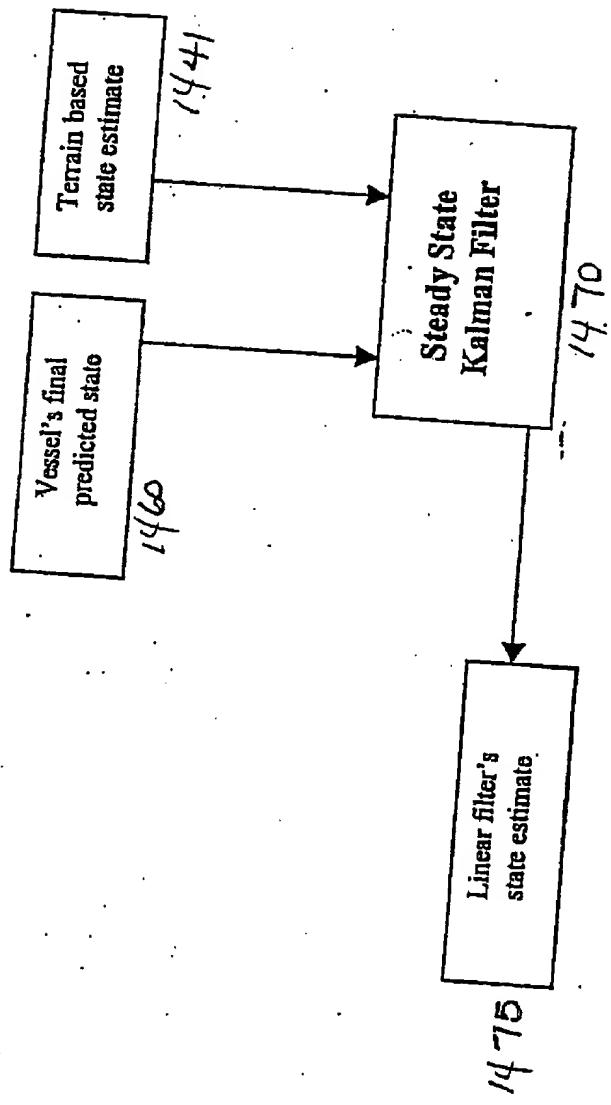
Figure 11





• Block diagram of the constrained extended Kalman filter subsystem  
showing the signal flow

Figure 13



Input/Output diagram for the steady state Kalman filter

Figure 14

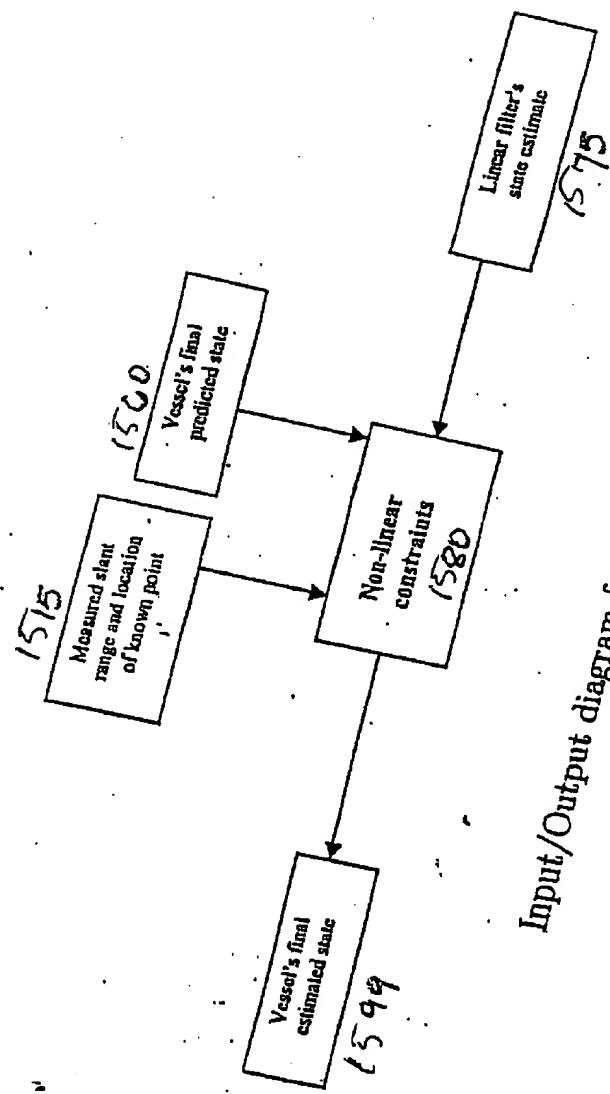
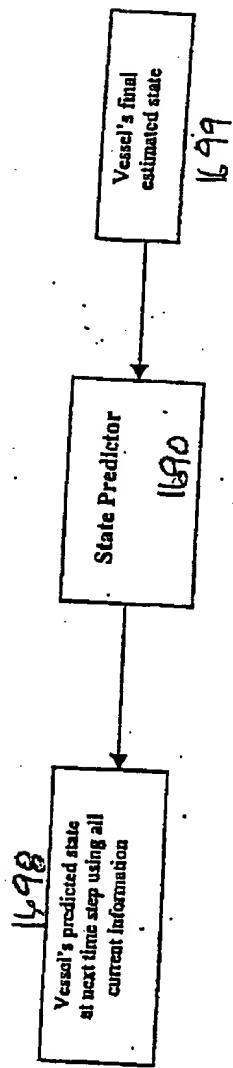


Figure 15  
Input/Output diagram for the nonlinear constraint module.



Input/Output diagram for the state predictor

FIGURE 16